

BUG ALGORITHM TO GUIDE WHEELCHAIR MOTION BASED ON OFFLINE ELECTRO-OCULOGRAPHY SIGNAL

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To my beloved father, mother, wife, son, and daughter.

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ABSTRACT

Certain disabled persons are not able to control the common powered wheelchair using joystick due to their limb movement restrictions. Hence, lots of current researches have studied other alternatives to control the powered wheelchair. Electrooculography (EOG) eye tracking control is one of the most ordinary alternative means to control the wheelchair because it offers a more natural mode to guide the wheelchair. Yet, it cannot be realized because users are normally not allowed to look around the surrounding environment during wheelchair motion. This is because the eye movements control the wheelchair while the user needs to look up to move forward, right to turn right, left to turn left and down to stop the wheelchair. In addition, this method exhausts the user due to the concentration needed during the navigation process. In this study, an automatic navigation approach alongside the manual method is proposed to guide the wheelchair by means of offline EOG signal. The automatic mode navigates the wheelchair from initial point to goal point while avoiding obstacles by employing Bug2 algorithm. Bug algorithms guide the robot from its starting point towards a preset goal point and avoid obstacles detected by sensors, and they do not require any other information about the environment in the navigation process. The EOG signals are measured, recorded, and analyzed using a biomedical measurement system (KL-720). The desired goal point direction and distance are calculated by analyzing horizontal and vertical gaze angles obtained. The hardware of the powered wheelchair is developed and modified so that it can be controlled automatically using EOG signal. The simulation done showed that Bug algorithms are able to guide the wheelchair to the desired destination based on only EOG signal. The new technique allows the user to look around without restraints, while the wheelchair is navigated automatically to the desired goal point.

ABSTRAK

Orang-orang kurang upaya yang tertentu tidak dapat mengawal kerusi roda berkuasa biasa menggunakan kayu bedik kerana kekangan pergerakan anggota badan mereka. Oleh itu, banyak kajian semasa telah mengkaji alternatif lain untuk mengawal kerusi roda berkuasa. *Electrooculography* (EOG) mata kawalan pengesanan adalah salah satu kaedah alternatif yang paling biasa untuk mengawal kerusi roda kerana ia menawarkan cara yang lebih semulajadi untuk mengawal kerusi roda. Namun, ia tidak boleh dicapai kerana pengguna biasanya tidak dibenarkan melihat persekitaran semasa gerakan kerusi roda. Ini adalah kerana pergerakan mata mengawal kerusi roda ketika pengguna perlu mencari untuk bergerak ke hadapan, kanan untuk belok kanan, kiri untuk belok kiri, dan ke bawah untuk menghentikan kerusi roda. Di samping itu, kaedah ini meletihkan pengguna disebabkan oleh konsentrasi yang diperlukan semasa proses navigasi. Dalam kajian ini, pendekatan navigasi automatik di samping kaedah manual dicadangkan untuk mengawal kerusi roda dengan cara isyarat EOG secara tidak atas talian. Mod automatik melayari kerusi roda dari titik awal ke titik matlamat dengan mengelak halangan menggunakan Bug2 algoritma. Algoritma-algoritma Bug membimbing robot dari titik permulaan ke arah satu titik matlamat pratetap dengan mengelak halangan dikesan oleh sensor, dan mereka tidak memerlukan apa-apa maklumat lain mengenai keadaan sekeliling dalam proses navigasi. Isyarat EOG diukur, direkodkan dan dianalisis dengan menggunakan sistem pengukuran bioperubatan (KL-720). Arah matlamat yang dikehendaki dan jarak dikira dengan menganalisa sudut-sudut pandangan yang diperolehi. Secara mendatar dan menegak. Perkakasan kerusi roda berkuasa dibangunkan dan diubahsuai agar ia dapat dikawal secara automatik menggunakan isyarat EOG. Simulasi yang telah dilakukan menunjukkan bahawa algoritma Bug dapat mengawal kerusi roda ke destinasi yang dikehendaki hanya berdasarkan isyarat EOG. Teknik baru ini membolehkan pengguna melihat sekeliling tanpa sekatan, manakala kerusi roda bergerak secara automatik ke titik matlamat yang dikehendaki.

TABLE OF CONTENTS

CHAPTER	TITLE	PAGE
	DECLARATION	ii
	DEDICATION	iii
	ACKNOWLEDGEMENT	iv
	ABSTRACT	v
	ABSTRAK	vi
	TABLE OF CONTENTS	vii
	LIST OF TABLES	x
	LIST OF FIGURES	xi
	LIST OF APPENDICES	xv
	LIST OF ABBREVIATIONS	xvi
1	INTRODUCTION	1
	1.1 Project Background	1
	1.2 Problem Statement	2
	1.3 Objectives	2
	1.4 Scopes of Study	2
	1.5 Project Significance	3
	1.6 Thesis Organization	4
2	LITERATURE REVIEW	5
	2.1 Introduction	5
	2.2 Powered Wheelchair	5
	2.2.1 Automatic Wheelchair Sensory	6
	2.2.2 Powered Wheelchair Motion Guide Approaches	10
	2.2.2.1 Joysticks Based	10
	2.2.2.2 Sip and Puff Based	11
	2.2.2.3 Voice Based	12

	2.2.2.4 Vision and Head Gesture Based	12
	2.2.2.5 EEG Based	13
	2.2.2.6 EMG and EOG Based	15
2.3	Electrooculography (EOG)	16
2.3.1	Anatomy and Physiology of Human Eyes	17
2.3.2	Configuration and Muscles Physiology of Human Eyes	18
2.3.3	Movement Properties of Human Eyes	19
2.3.4	Eye Movement Signal Potentials	19
2.3.5	Electrooculography Signal Recording	21
2.4	Path Finding Algorithms	23
2.4.1	Dijkstra's Algorithm	23
2.4.2	Heuristic Search Algorithms	24
2.4.3	Bug Algorithms	25
	2.4.3.1 Bug2 Algorithm	27
	2.4.3.2 Tangent-Bug Algorithm	28
2.5	Summary	32
3	METHODOLOGY	33
3.1	Study Planning	33
3.2	EOG Signal Measurement System	35
3.2.1	Tools and Experimental Setting	35
3.2.2	Experimental Setup for EOG Signal Measurement	37
3.2.3	EOG Signal Process and Analysis	42
3.3	Goal Point Distance and Position Measurements	43
3.4	The Wheelchair Hardware	48
3.4.1	Arduino Uno Board	48
3.4.2	Motor Driver	49
3.4.3	Sensor	51
3.4.4	Rotary Encoder	54
3.5	Software Developments and Implementations	56
3.5.1	Design of Initial Turning Direction	58
3.5.2	Sensors Control	59

3.5.3	Motors Control	60
3.5.4	Rotary Encoder Control	61
3.5.5	Bug2 Programming	63
3.5.6	Tangent-Bug Programming	64
3.6	Summary	66
4	RESULT AND DISCUSSION	67
4.1	Measurement of EOG signal	67
4.2	Tangent-Bug and Bug2 Algorithms Simulation and Comparison	73
4.3	System Software Calibrations	77
4.3.1	Turning Direction Based on Gaze Angle	77
4.3.2	Reading Distance from IR Sensors	78
4.3.3	Controlling Wheelchair Motor	79
4.3.4	Reading Pulse of Rotary Encoder to Calculate Travelled Distance	80
4.3.5	Wheelchair Motion Guide	81
4.4	Summary	85
5	CONCLUSION AND RECOMMENDATION	87
5.3	Conclusion	87
5.4	Recommendation for Future Work	88
	LIST OF PUBLICATIONS	89
	REFERENCES	91
	Appendices A-F	101 - 172

LIST OF TABLES

TABLE NO.	TITLE	PAGE
3.1	List of connections from KL-72001 main unit to KL-75003 EOG module	37
3.2	Change of d values based on the change of β and α values, at fixed $h = 150$ cm	46
3.3	α threshold values	47
3.4	β threshold values	48
3.5	Motor driver input values to control speed and direction	61
4.1	Result of wheel rotation and wheelchair movement	79

LIST OF FIGURES

FIGURE NO.	TITLE	PAGE
2.1	The Wheelesley wheelchair	7
2.2	Sensors placement of Wheelesley	7
2.3	Robotic wheelchair with sensor configuration	8
2.4	SENA wheelchair	8
2.5	Ghost echo problem with sonar sensor	9
2.6	Wheelchair joystick controls (a) Common joystick (b) Finger control (c) Touchpad drive control (d) Board with buttons control	10
2.7	Wheelchair Specialty Controls: (a) Chin-control, (b) Head Control	11
2.8	Sip-and-Puff wheelchair control method	11
2.9	Vision based wheelchair control	13
2.10	Wheelchair control based on EEG signal	14
2.11	HCI system input screen interface	16
2.12	Anatomy and parts of the human eye	17
2.13	The muscle physiology of the eye	18
2.14	Signal of eye movement potentials ; i) Downward eye movement, ii) Upward eye movement, iii) Leftward eye movement and iv) Rightward eye movement (Connell, 2007).	20
2.15	EOG electrode placement on the subject face	21
2.16	EOG horizontal signal produced from eye movement with different angles (Kherlopian <i>et al.</i> , 2006)	22
2.17	Gaze angle representation in the EOG measurement system	22
2.18	Blink detection by the EOG measurement system	23

2.19	Dijkstra's algorithm: notice that all nodes are visited in terms to find the shortest path	24
2.20	A close-up of a path planned using Field D* showing individual grid cells, (Ferguson and Stentz, 2005)	25
2.21	M-line representation	27
2.22	Navigation process based on Bug2 algorithm	28
2.23	Illustration of robot equipped with range sensor concept	29
2.24	Navigation process based on Tangent-Bug algorithm	29
2.25	Paths for Bug algorithms on setting (A)	30
2.26	Paths for Bug algorithms in setting (B)	31
3.1	Flow chart of the study	34
3.2	KL-720 biomedical measurement system	35
3.3	Block diagram of EOG acquisition and processing	36
3.4	KL-75003 EOG module connection with KL-72001 main unit	38
3.5	(a) Disposable EOG electrode with Ag/AgCl, (b) Electrodes, (c) KL-79101 5-Conductor Electrode Cable	39
3.6	Electrode placements	40
3.7	Oscilloscope showing EOG signal measurements	40
3.8	The subject at an exact distance (d) from the wall with the arrangement for the EOG recording system, which demonstrates five points of view	41
3.9	The subject at an exact distance (d) from the wall with the arrangement for the EOG recording system, which demonstrates gaze angle points	41
3.10	EOG measurement experimental setup	42
3.11	Goal point angle measurement (Side view)	43
3.12	Goal point distance measurement (Top view)	44
3.13	Available goal points to be targeted by the user	45
3.14	Arduino Uno board	49
3.15	MD30B motor driver	50

3.16	Motor driver interface with Arduino Uno	51
3.17	Block diagram of IR sensor	52
3.18	GP2Y0A21YK0F Sharp IR sensor	52
3.19	IR sensor interface with Arduino Uno	53
3.20	IR Sensor holder on the wheelchair	53
3.21	Mouse rotary encoder	54
3.22	Encoder interface with Arduino Uno	55
3.23	Rotary encoder and its holder	55
3.24	Flow chart diagram for controlling the wheelchair based on EOG signal	56
3.25	Outline of the wheelchair inputs and outputs	57
3.26	Work flow chart of the project	58
3.27	Graph of output voltage to distance of reflective object	59
3.28	Position of crossing IR sensors at the wheelchair	60
3.29	Pulse width modulation signal	60
3.30	Rotary encoder and roller configuration at wheelchair	62
3.31	Shaft is rotating clockwise	62
3.32	Shaft is rotating counter clockwise	63
3.33	Navigation behavior in Bug2 algorithm	63
3.34	Navigation behavior in Bug2 algorithm	65
4.1	EOG output waveform of center-rest point (C)	68
4.2	EOG output waveform of blink (B)	68
4.3	EOG output waveform of upward eye movement (U)	69
4.4	EOG output waveform of downward eye movement (D)	69
4.5	EOG output waveform of leftward eye movement (L)	70
4.6	EOG output waveform of rightward eye movement (R)	71
4.7	EOG output waveform of -10° horizontal gaze angle	71
4.8	EOG output waveform of -20° horizontal gaze angle	72

4.9	EOG output waveform of -30° horizontal gaze angle	72
4.10	EOG output waveform of -40° horizontal gaze angle	72
4.11	Virtual map and navigation process (case A)	74
4.12	Virtual map and navigation process (case B)	74
4.13	Virtual map and navigation process (case C)	75
4.14	Bug2 algorithm simulation (tactile sensor)	75
4.15	Tangent-Bug algorithm simulation (range sensor)	76
4.16	Initial State before the program is executed, all LEDs are off	77
4.17	“Left” red LED turns on when $\alpha = -20^\circ$	77
4.18	“Forward” yellow LED turns on when $\alpha = 0^\circ$	78
4.19	“Right” green LED turns on when $\alpha = 20^\circ$	78
4.20	(a) Two green LEDs switch on when no obstacle detected within 35 cm, (b) An obstacle detected less than 35 cm by left sensor, (c) An obstacle detected within 35 cm by right sensor	79
4.21	Serial monitor of Arduino Uno boot loader	80
4.22	Wheelchair motion	81
4.23	The wheelchair moves forward from initial state	82
4.24	The IR sensors sense obstacle within the range. Wheelchair stops and boundary following behavior is triggered	82
4.25	After sensing an obstacle, the wheelchair turns left to avoid the obstacle	82
4.26	The wheelchair stops when obstacle is no longer detected	83
4.27	The wheelchair turns right to follow the boundary of the obstacle	83
4.28	The wheelchair begins to turn right	83
4.29	The wheelchair detects the obstacle again and avoids it	84
4.30	Wheelchair meets the M-line again and starts to follow the path	84
4.31	The wheelchair reaches the goal point then stops	84
4.32	60° detection area	85

LIST OF APPENDICES

APPENDIX	TITLE	PAGE
A	KL-720 biomedical measurement system	101
B	Arduino UNO microcontroller data sheet	114
C	Enhanced motor driver (MD30B) data sheet	116
D	Sharp IR GP2Y0A02YK0F range sensor data sheet	120
E1	Programming code of initial turning direction based on eye gaze angle	122
E2	Programming code of reading signal from IR sensor	125
E3	Programming code of controlling motors	129
E4	Programming code of reading pulse signal from rotary encoder	131
E5	The complete navigation programming code for Bug2	132
F	The Complete MATLAB Code for Tangent-Bug	140

LIST OF ABBREVIATIONS

NFIC	-	New Freedom Initiative Act
ALS	-	Amyotrophic Lateral Sclerosis
EMG	-	Electromyography
EOG	-	Electrooculography
EPW	-	electric-powered wheelchair
IR	-	Infrared
EEG	-	Electroencephalography
BCI	-	brain-computer interfaces
HCI	-	Human Computer Interfaces
ECG	-	Electrocardiogram
ERG	-	Electroretinogram
CSV	-	Comma Separated Values
GUI	-	graphical user interface
PWM	-	pulse-width modulations
USB	-	Universal Serial Bus
CW	-	clockwise rotation
CCW	-	counterclockwise rotation
GND	-	Ground
IREDD	-	Infrared Emitting Diode
PSD	-	Position Sensitive Detector

CHAPTER 1

INTRODUCTION

1.1 Project Background

The New Freedom Initiative Act (NFIC) approximated that, aged and disabled individuals whom necessitate for wheelchair are more than 100 million global. The common powered wheelchairs; that are guided using joystick, are not handy for the disabled with limb movement restrictions such as spinal cord injury and amyotrophic lateral sclerosis (ALS). Hence, an alternative approaches are investigated to help those disabled and elderly who cannot use the manual powered wheelchair. These alternative approaches concentrated on guiding the wheelchair by means of other body signals and other body parts that are not defected.

Among the guiding approach substitutes are: controlling a wheelchair by means of head gestures suggested by Wei (2004), (Matsumotot *et al.*, 2001), Nakanishi *et al.* (1999) and Kuno *et al.* (2001); guiding by means of voice recognition by (Levine *et al.*, 1999; Cagigas and Abascal, 2004); a guide based on the Electromyography (EMG) signal proposed by Felzer and Freisleben (2002) and Moon *et al.* (2005); and Electrooculography (EOG) eye tracking control presented in the literature by Mazo (2001).

1.2 Problem Statement

The EOG eye tracking guide presents a more likely and natural manner to control the wheelchair. Still, it is neglected, for the reason that the wheelchair user is not capable to look or gaze at the nearby atmosphere throughout the navigation route, which is very exhausting for the user's eyes. Hence, several researchers such as Hashimoto *et al.* (2009) and Tsui *et al.* (2008) attempted to rise above this difficulty by utilizing the EMG signal, which control direction; in addition to the EOG signal, which control speed to guide the wheelchair. In this research, the powered wheelchair is guided by means of eye gazes and blinks. Bug algorithm is utilized to navigate the wheelchair automatically to the desired goal point.

1.3 Objectives

This study aims to assist those people with serious disabilities to advance their mobility and substantially enhance their living quality. The main objective of this study is to guide the wheelchair motion based on EOG signal. Yet, the wheelchair user will be able to look around and surround, due to the hands-free control system that uses only eyes gaze and blinks to control the powered wheelchair. For this to be achieved, the following objectives need to be attained:

1. Develop powered wheelchair hardware and software, which can be controlled based on EOG signal.
2. Record, and analyze eye movements by means of the EOG signal measurement system.

1.4 Scopes of Study

A wheelchair motion guide based on EOG signal is a recent study topic. EOG offers a lot of possibilities and functions beside the wheelchair motion guide is a promising research area. The scope of this study contains:

1. Review on powered wheelchairs and approaches used to control them, including EOG signal which is applied in this study. The EOG signal used in this research is offline signal.
2. Study and compare path finding algorithms including Bug algorithms, which are implemented in our project. Bug2 and Tangent-Bug are simulated, and the wheelchair is guided automatically by means of Bug2 algorithm.
3. Development of the automatic wheelchair's hardware, and software. Hardware includes sensors, motor drivers, rotary encoder, microcontroller, and the interface among these parts with the wheelchair. While software includes programming the microcontroller to read all inputs and also to utilize the Bug algorithm.
4. Investigate the eye movement tracking and recording based on the EOG signal measurement system. Also, utilize the gaze angles and blinks measured to control the wheelchair automatically and manually.

1.5 Project Significance

A new automatic controlling method is introduced beside the common manual method. In the automatic controlling mode, the user gazes at the desired destination, then blink to send the signal to the wheelchair to start navigating. Bug2 algorithm is utilized to control the wheelchair in automatic guide mode.

This work is conducted especially to rise above the drawback of the typical powered wheelchair controlled based on EOG signal. The user can enjoy looking at the neighboring environment freely during the wheelchair motion process.

1.6 Thesis Organization

After acknowledging the requirement to fulfill the perception of this study, this thesis has been written and accumulated with the optimum effort in terms to attain the ease of the reader. This report includes six chapters with the brief outline of each chapter as stated as follows:

Chapter 1 serves as an introduction to this research; it includes the background of the project, problem statements, objectives of the research, and scopes of the study.

After that, Chapter 2 provides literature reviews from previous research work from other researches on powered wheelchair motion guides, path finding algorithms and EOG signal.

And Chapter 3 has been utilized to explain and discusses the methodology applied in this project, including the project planning and measurements of EOG signal ; the hardware, and software of the wheelchair; as well as calibration and development of the controlling method based on Bug2 algorithm.

In Chapter 4, the findings and simulation of this project are demonstrated and examined together with the indication to strengthen the results of the study.

The last chapter, particularly Chapter 5 ceases the entire contents of this thesis and provides the conclusions and recommendations on researches that may be directed at the time ahead.

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